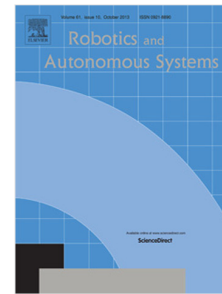


## Accepted Manuscript

Integrated online trajectory planning and optimization in distinctive topologies

Christoph Rösmann, Frank Hoffmann, Torsten Bertram



PII: S0921-8890(16)30049-5  
DOI: <http://dx.doi.org/10.1016/j.robot.2016.11.007>  
Reference: ROBOT 2743

To appear in: *Robotics and Autonomous Systems*

Received date : 31 January 2016  
Accepted date : 10 November 2016

Please cite this article as: C. Rösmann, et al., Integrated online trajectory planning and optimization in distinctive topologies, *Robotics and Autonomous Systems* (2016), <http://dx.doi.org/10.1016/j.robot.2016.11.007>

This is a PDF file of an unedited manuscript that has been accepted for publication. As a service to our customers we are providing this early version of the manuscript. The manuscript will undergo copyediting, typesetting, and review of the resulting proof before it is published in its final form. Please note that during the production process errors may be discovered which could affect the content, and all legal disclaimers that apply to the journal pertain.

# Integrated Online Trajectory Planning and Optimization in Distinctive Topologies

Christoph Rösmann<sup>a,\*</sup>, Frank Hoffmann<sup>a</sup>, Torsten Bertram<sup>a</sup>

*<sup>a</sup>Institute of Control Theory and Systems Engineering  
Technical University of Dortmund  
44227 Dortmund, Germany*

---

## Abstract

This paper presents a novel integrated approach for efficient optimization based on online trajectory planning of topologically distinctive mobile robot trajectories. Online trajectory optimization deforms an initial coarse path generated by a global planner by minimizing objectives such as path length, transition time or control effort. Kinodynamic motion properties of mobile robots and clearance from obstacles impose additional equality and inequality constraints on the trajectory optimization. Local planners account for efficiency by restricting the search space to locally optimal solutions only. However, the objective function is usually non-convex as the presence of obstacles generates multiple distinctive local optima.

The proposed method maintains and simultaneously optimizes a subset of admissible candidate trajectories of distinctive topologies and thus seeking the overall best candidate among the set of alternative local solutions. Time-optimal trajectories for differential-drive and carlike robots are obtained efficiently by adopting the Timed-Elastic-Band approach for the underlying trajectory optimization problem. The investigation of various example scenarios and a comparative analysis with conventional local planners confirm the advantages of integrated exploration, maintenance and optimization of topologically distinctive trajectories.

---

\*Corresponding author

Email address: [christoph.roesmann@tu-dortmund.de](mailto:christoph.roesmann@tu-dortmund.de) (Christoph Rösmann)

Download English Version:

<https://daneshyari.com/en/article/4948897>

Download Persian Version:

<https://daneshyari.com/article/4948897>

[Daneshyari.com](https://daneshyari.com)